

IN THE DRAWINGS

Please amend Fig. 1 according to the REPLACEMENT SHEET submitted herein.

The diagram illustrates a mechanical assembly, possibly a prosthetic arm or a robotic limb, labeled FIG. 1. The assembly includes a base component (5) which houses a motor or actuator (35). A long, curved member (6) is connected to the base via a joint (40). This member is further connected to a series of links and joints forming a kinematic chain. Key components include a pivot point (16), a link (7), a joint (13), a link (26), a joint (21), a link (28), a joint (11), a link (14), and a joint (29). A thick curved line (41) indicates a path or trajectory. A coordinate system is defined by three axes: E (vertical), L (horizontal), and T (diagonal).

FIG. 1